Amendments to the claims:

The following listing of claims replaces all prior versions of the claims:

1. (Currently Amended) A method of embedding images from other sources within images captured by a viewing device in motion, by transmitting and analyzing the positional coordinates of the viewing device during acquisition of a sequence of video images (I) while the viewing device is moving through space along a trajectory (t) determined with respect to a defined reference point, the method comprising:

a ~~prelimary~~ preliminary step consisting of attaching said viewing device to a first subsystem which contains an inertial sensing unit delivering data signals representing spatial coordinates and instantaneous inclination and the focal ~~lenght~~ length of said viewing device with respect to said defined reference point;

a first step of acquiring, in real time, of said data signals during the movement of said viewing device along said trajectory (*t*) and the ~~transmision~~ transmission of said data signals to a second subsystem which includes equipment for processing said data signals using a stored software program, wherein the equipment is a module removable from the viewing device; and

a second step of processing said data signals, either in real time or deferred for later analysis, so as to determine said spatial coordinates of ~~position~~ the viewing device, and improving the quality of the acquired data signals by applying an image analysis procedure.

2. (Currently Amended) The method, according to claim 1, wherein said spatial coordinates represent the position of said viewing device along said trajectory (*t*) in relation to the axes of said orthonormal trihedron of reference (*XYZ*) and the instantaneous inclination [[data]] represents the angles of azimuth, elevation and roll

around the axis of said ~~viesing~~ viewing device, said axis intersecting the center (C) of the

focal plane (FP) of said sequence of video images (I).

3.   (Currently Amended) The method, according to ~~claims~~ claim 1, wherein, during a

supplementary preliminary step, said inertial sensing unit is initialized and standardized

with respect to a reference point of origin.

4.   (Withdrawn - Currently Amended) The method of claim 1, wherein [[the]] error

corrections to [[said]] positional data streams delivered by said inertial sensing unit[[.]] is

done by applying [[an]] the image ~~anaysis~~ analysis procedure, included among the stored

software program contained in [[the]] a data processing unit.

5.   (Withdrawn - Currently Amended) The method of claim 1, wherein the integration of

the focal planes *(FP)* of the sequence of video images (*I*) is obtained by acquiring data

identifying the focal length used by said viewing device and by capturing, in real time, the

data signals representing the spatial coordinates and the instantaneous inclination of said

viewing device.

6.   (Withdrawn – Currently Amended) The method according to claim 1, wherein [[,]]

the data signals and the focal length are used in a manner so as to visualize, in real time,

the images captured by said viewing device into a preexisting three-dimensional virtual

décor by using software for three dimensional reconstitution .

7.   (Withdrawn – Currently Amended) A method of claim 1, wherein ~~it is include~~

connecting devices for transmitting the signals from the first to the second subsystem are

included for transmitting the signals from the first subsystem to the second subsystem.

8. (Withdrawn – Previously Presented) The method of claim 1, wherein the viewing device is a video camera.

9. (Withdrawn - Currently Amended) The method of ~~claims~~ claim 1, wherein the inertial sensing unit includes at least one gyrometer and one accelerometer with three distinct, non-coplanar axes.

10. (Withdrawn - Currently Amended) The method of ~~claims~~ claim 9, wherein in order to improve the determination of spatial coordinates of the viewing device and to improve the synchronization between the acquired data and the sequence of video images (I) obtained comprises at least one of the following components[[;]]:

[[A]] a tri-flux rotary magnetometer;

[[Two]] two inclinometers, orthogonal with respect to each other;

[[A]] a satellite localization device of the "GPS" type;

[[An]] an electronic localization device, using either electromagnetic or electrostatic fields;

[[A]] a magnetometer of one or several fluxes, either static or dynamic;

[[An]] an odometer;

[[A]] a temperature sensor;

[[A]] a precision quartz timer;

[[An]] an auxiliary video camera, attached to said first subsystem, and

[[A]] a microphone.

11. (Currently Amended) The method of claim 4, further comprising improving the quality of the said acquired data signals by applying [[an]] the image analysis procedure, included among the stored software program which is included in the data processing unit.

12. (Currently Amended) The method of claim 1, further comprising a supplementary preliminary step consists of storing [[the]] said acquired data within [[the]] a hard drive data storage module of [[the]] said data processing unit.